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ON THE REDUCTION OF DIMENSIONALITY
OF A GENERAL CLASSICAL THREE-BODY PROBLEM

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О сокращении размерности общей классической задачи трех тел

Уменьшение размерности общей классической задачи трех тел рассматривается в рамках идеи разделения внутреннего и внешнего движения системы тел. Ввиду того, что для гамильтоновой системы существует эквивалентность между фазовыми траекториями и геодезическими траекториями на римановом многообразии \mathcal{M} (поверхность Лагранжа системы тел), классическая задача трех тел сформулирована в рамках шести обыкновенных дифференциальных уравнений (ОДУ) второго порядка на тангенциальном расслоении многообразия \mathcal{M}_t . Показано, что в том случае, когда общий потенциал взаимодействия системы тел зависит от относительных расстояний между частицами, три из шести геодезических уравнений, описывающих вращения образованного тремя телами треугольника, решаются точно. С помощью этого факта было доказано, что общая задача трех тел может быть описана в рамках трех нелинейных ОДУ канонического вида. Показано, что редуцированная задача описывает динамику системы трех тел на плоскости рассеяния с учетом полного углового момента вращающегося треугольника тел. На многообразии \mathbb{R}^3 (пространство относительных расстояний между частицами) получены явные виды уравнений геодезических отклонений. Для нахождения гомографических решений ограниченной задачи трех тел получена система алгебраических уравнений. Найдены начальные и асимптотические условия для решения классической задачи рассеяния.

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On the Reduction of Dimensionality of a General Classical Three-Body Problem

The reduction of dimensionality of the general three-body classical problem is considered in the framework of the ideas of separation of the internal and external motions of the body system. Based on the fact that for a Hamiltonian system there exists equivalence between phase trajectories and geodesic trajectories on the Riemannian manifold \mathcal{M} (the Lagrangian surface of the body system), the classical three-body problem is formulated in the framework of six ordinary differential equations (ODEs) of the second order on the tangential bundle of the Lagrange manifold \mathcal{M}_t . It is shown that in the case when the total interaction potential of the body system depends on the relative distances between particles, three out of the six geodesic equations describing rotations of the triangle formed by three bodies are solved exactly. Using this fact it was proved that the general three-body problem can be described in the limits of three nonlinear ODEs of canonical kind. It is shown that the reduced problem describes the dynamics of the three-body system on the scattering plane with consideration of the total angular momentum of the rotating body triangle. The equations of geodesic deviations on the manifold \mathbb{R}^3 (the space of relative distances between particles) are derived in explicit form. A system of algebraic equations for finding homographic solutions of the restricted three-body problem is obtained. The initial and asymptotic conditions for solution of the classical scattering problem are found.

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INTRODUCTION

The general three-body classical problem concerns the question of understanding the motions of three arbitrary point masses traveling in space according to Newton's laws of mechanics. Many works on analytical mechanics, celestial mechanics, stellar and molecular dynamics (see [1–9]) are devoted to the study of this problem. Note that most thoroughly, in particular theoretically and numerically, the three-body problem was studied in the case of a restricted problem when one of the masses is negligible compared to the other two masses. In this case, the problem is naturally reduced to the two-body problem, which was first exactly solved by Newton in his *Principia* in 1687. For solution of the general problem, different approaches based on series expansions methods have been proposed; however, due to the poor convergence of these expansions they are often used and are useful only for solving of particular problems where the system of three bodies is in a stable bound state [2, 10]. Moreover, the three-body problem is a typical example of a dynamic system where on the large scales of the phase space we observe all features of a complex motion including the bifurcation and chaos. That makes the numerical simulation method a basic way of research of the mentioned problem.

Thus, we can say that despite the centuries of exploration, there is no solution to the general three-body problem as there are no coordinate transformations that can simplify the problem; unlike the two-body problem or the restricted three-body problem, the motion of each body has to be considered along with the motions of the other two bodies because the vectors of the mutual forces do not line up with the center of mass.

Let us note that the general problem of three bodies with consideration of specifics of the multichannel scattering differs by additional complexities, which are associated primarily with the need for numerical simulation of the problem for an infinite number of initial data. In other words, for numerical investigation of the problem, if this is possible, it is important to reduce the dimensionality of the problem which allows one to reduce the volume of calculations and make them true and accurate.

The problem of separating the vibration motions from the collective motions, i.e., the translational and rotational motions of the molecular system, has been under continuous attention in both classical and quantum mechanics. In any case, the problem of separation of motions in a molecular system makes one study what is meant by the Eckart condition of the translational and rotational motions [11–13]. In particular, in work [14] the vibration motions were defined rigorously, and it was thereby shown that the vibration motions cannot be separated from the rotation motions in the theory of connections in differential geometry. In paper [15], on the basis of the connection theory for the center-of-mass coordinate system, it was proved that the Eckart frame exists for any configuration of the molecule but not uniquely. Moreover, as is shown in this work, one can choose a moving frame relative to which the molecule moves without rotation.

In Krylov's outstanding work [16], where statistical properties of a dynamical system consisting of N classical particles (gas relaxation) are studied, for the first time geodesic flow on the Lagrangian surface of a system of particles was used. Later, by means of this method, statistical properties of non-Abelian Yang–Mills gauge field [17, 18] and relaxation properties of stellar systems [19, 20] were studied in detail.

The main aim of the present work is to find new opportunities for separation of the internal and collective motions in the general classical three-body problem, which will be of key importance for the reducing of the dimensionality of the studied dynamical problem. Following aforementioned works [19, 20], we have used the geodesic trajectories approach on the Lagrangian surface of a three-body system to describe the coupling between the rotational and internal motions at the collision of bodies. We have shown the possibility of nontrivial separation of motions in the general three-body problem on the Lagrangian surface of a body system. It should be noted that for the first time the reducing of the dimensionality of the classical three-body problem has been made on the basis of heuristic considerations at the investigation of the problem of quantum chaos in the system of three bodies [21].

In this work, we have strictly proven the possibility of reducing the dimensionality of the general three-body classical problem twice (from the 6D to 3D) and also developed new ideas for studies of the restricted and scattering problems.

1. FORMULATION OF THE PROBLEM

1.1. Reduction of the Problem of Multichannel Scattering to the Problem of Motion of Effective Mass in 6D Configuration Space. The 3D classical three-body problem in a most general formulation as the problem of multichannel scattering with several possible outcomes can be represented

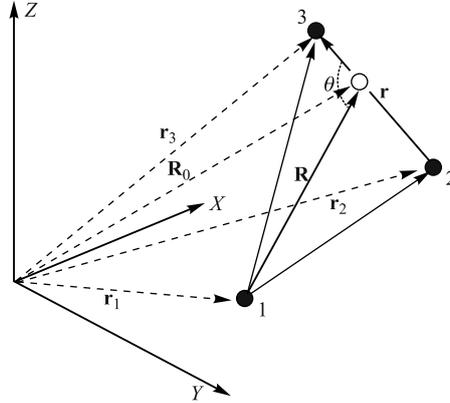
as the scheme of multichannel scattering:

$$1 + (23) \rightarrow \begin{cases} 1 + (23), \\ 1 + 2 + 3, \\ (12) + 3, \\ (13) + 2, \\ (123)^* \rightarrow \begin{cases} 1 + (23), \\ 1 + 2 + 3, \\ (12) + 3, \\ (13) + 2, \end{cases} \end{cases}$$

where the numbers 1, 2 and 3 denote colliding particles; the brackets (...) and (...) * denote two particles in bound state and the short-living resonance, correspondingly. It is obvious that the investigation of short-living resonance (123)* is close to the restricted problem of three bodies. The classical Hamiltonian of a three-body system in the Cartesian coordinates system (see figure) has the following form:

$$H = \sum_{i=1}^3 \frac{\mathbf{p}_i^2}{2m_i} + V(\mathbf{r}_1, \mathbf{r}_2, \mathbf{r}_3), \quad (1)$$

where $(\mathbf{r}_1, \mathbf{r}_2, \mathbf{r}_3)$ and $(\mathbf{p}_1, \mathbf{p}_2, \mathbf{p}_3)$ are position vectors and momenta of the corresponding particles, respectively; (m_1, m_2, m_3) are their masses; and $V(\mathbf{r}_1, \mathbf{r}_2, \mathbf{r}_3)$ denotes the total interaction potential between the particles. It will be assumed



The Cartesian coordinates system where the set of vectors \mathbf{r}_1 , \mathbf{r}_2 and \mathbf{r}_3 denotes coordinates of particles 1, 2 and 3, respectively. The \circ is the center of mass of pair (12) which in the Cartesian system is expressed by \mathbf{R}_0 . The Jacobi coordinates system described by the radius-vectors \mathbf{R} and \mathbf{r} , in addition to θ , denote scattering angle

that the total interaction potential of the body system depends on the relative distances between the particles:

$$V(\mathbf{r}_1, \mathbf{r}_2, \mathbf{r}_3) \equiv V(\|\mathbf{r}_{12}\|, \|\mathbf{r}_{13}\|, \|\mathbf{r}_{23}\|), \quad (2)$$

where $\mathbf{r}_{12} = \mathbf{r}_1 - \mathbf{r}_2$, $\mathbf{r}_{13} = \mathbf{r}_1 - \mathbf{r}_3$ and $\mathbf{r}_{23} = \mathbf{r}_2 - \mathbf{r}_3$ are relative distances between the particles; in the particular case, the total potential can consist of pair potentials $V(\mathbf{r}_1, \mathbf{r}_2, \mathbf{r}_3) = V_{12}(\|\mathbf{r}_{12}\|) + V_{13}(\|\mathbf{r}_{13}\|) + V_{23}(\|\mathbf{r}_{23}\|)$.

After the Jacobi coordinates transformation, Hamiltonian (1) acquires the form

$$H = \sum_{k=1}^3 \frac{\mathbf{P}_k^2}{2\mu_k} + V'(\mathbf{r}, \mathbf{R}), \quad V'(\mathbf{r}, \mathbf{R}) = V(\|\mathbf{R} - \lambda_- \mathbf{r}\|, \|\mathbf{R} + \lambda_+ \mathbf{r}\|, \|\mathbf{r}\|), \quad (3)$$

where $\mathbf{r} = \mathbf{r}_2 - \mathbf{r}_3$ is the relative position of particle 2 to particle 3; $\mathbf{R} = \mathbf{r}_1 - \mathbf{R}_0$ is the relative position of particle 1 to the center of mass of pair (23) the radius vector of which is defined by the expression $\mathbf{R}_0 = (m_2 \mathbf{r}_2 + m_3 \mathbf{r}_3)/(m_2 + m_3)$. In addition, the following designations are made:

$$\begin{aligned} \mathbf{P}_1 &= \mathbf{p}_1 + \mathbf{p}_2 + \mathbf{p}_3, & \mathbf{P}_2 &= \frac{m_3 \mathbf{p}_2 - m_2 \mathbf{p}_3}{m_2 + m_3}, \\ \mathbf{P}_3 &= \frac{(m_2 + m_3) \mathbf{p}_1 - m_1 (\mathbf{p}_2 + \mathbf{p}_3)}{\mu_1}, \\ \mu_1 &= m_1 + m_2 + m_3, & \mu_2 &= \frac{m_2 m_3}{m_2 + m_3}, & \mu_3 &= \frac{m_1 (m_2 + m_3)}{\mu_1}, \\ \lambda_- &= \frac{\mu_2}{m_2}, & \lambda_+ &= \frac{\mu_2}{m_3}, \end{aligned}$$

where \mathbf{P}_1 describes the total momentum of the three-body system; $\mathbf{P}_2 = \mu_2 \dot{\mathbf{r}} = \mu_2 d\mathbf{x}/dt$ is the momentum of the center of mass of pair (23); and $\mathbf{P}_3 = \mu_3 \dot{\mathbf{R}} = \mu_3 d\mathbf{R}/dt$ is correspondingly the momentum of the effective mass μ_3 which describes the three-body configuration 1 + (23).

After deleting the motion of the center of mass of the three-body system (that is equivalent to the condition $\mathbf{P}_1 = 0$) [22, 23], we can find for the Hamiltonian the following expression:

$$\tilde{H} = \frac{1}{2\mu_0} \sum_{k=2}^3 \tilde{\mathbf{P}}_k^2 + V'(\mathbf{r}, \mathbf{R}), \quad (4)$$

where

$$\mu_0 = \sqrt{\frac{m_1 m_2 m_3}{\mu_1}}, \quad \tilde{\mathbf{P}}_2 = \sqrt{\mu_2 \mu_0} \dot{\mathbf{r}}, \quad \tilde{\mathbf{P}}_3 = \sqrt{\mu_3 \mu_0} \dot{\mathbf{R}}.$$

More clearly, Hamiltonian (4) can be represented as

$$\begin{aligned}\tilde{H}(\mathbf{P}_{\mathbf{x}_1}, \mathbf{P}_{\mathbf{x}_2}; \mathbf{x}_1, \mathbf{x}_2) &= \frac{1}{2\mu_0}(\mathbf{P}_{\mathbf{x}_1}^2 + \mathbf{P}_{\mathbf{x}_2}^2) + \tilde{V}(\mathbf{x}_1, \mathbf{x}_2) = \\ &= \mathcal{H}(\mathbf{P}_{\mathbf{x}}; \mathbf{x}) = \frac{1}{2\mu_0}\mathbf{P}_{\mathbf{x}}^2 + U(\mathbf{x}),\end{aligned}\quad (5)$$

where

$$\mathbf{x}_1 = \sqrt{\mu_2/\mu_0}\mathbf{r}, \quad \mathbf{x}_2 = \sqrt{\mu_3/\mu_0}\mathbf{R}, \quad \mathbf{x} = (\mathbf{x}_1, \mathbf{x}_2)^T = \mathbb{R}^6;$$

in addition, $(\dots)^T$ designates the transposed vector, $\mathbf{P}_{\mathbf{x}_1} \equiv \tilde{\mathbf{P}}_2$, $\mathbf{P}_{\mathbf{x}_2} \equiv \tilde{\mathbf{P}}_3$, and $U(\mathbf{x}) = \tilde{V}(\mathbf{x}_1, \mathbf{x}_2) \equiv V'(\mathbf{r}, \mathbf{R})$.

Thus, the three-body scattering problem can be reduced to the problem of motion of imaginary point with the effective mass μ_0 on the six-dimensional configuration manifold \mathbb{R}^6 .

1.2. The Equation of Motion on the Lagrangian Surface of a Three-Body System. As is easy to see, the classical system of three bodies at their motion in the 3D Euclidean space permanently forms a triangle, and Newton's equations describe the dynamical system on the space of such triangles. This means that we can formally consider the motion of a body system consisting of two parts. The first is the rotational motion of the body-triangle in the 3D Euclidean space and the second is the internal motion of bodies on the plane defined by the triangle. It follows that theoretically the aforementioned motions can be separated by introducing a nontrivial moving coordinate frame.

Mathematically, the configuration manifold of solid body \mathbb{R}^6 can be represented as a direct product of two subspaces [24]:

$$\mathbb{R}^3 \times S^3 \Leftrightarrow \mathbb{R}^6,$$

where \mathbb{R}^3 is the manifold which is defined as an orthonormal space of relative distances between the bodies (the internal space), while S^3 denotes the space of rotation group $SO(3)$ (the external space). However, in the considered problem the connections between the bodies are not holonomic and, correspondingly, the configuration manifold \mathbb{M} must be different:

$$\mathbb{M} \cong \mathcal{M}_t \times S^3 \subset \mathbb{R}^6, \quad \mathcal{M}_t \subset \mathbb{R}^3,$$

where the manifold \mathcal{M}_t denotes a space of relative distances between moving bodies (see definition (7)).

Let us now introduce a local system of generalized coordinates:

$$(x^1, x^2, x^3, x^4, x^5, x^6) \in \mathbb{M},\quad (6)$$

where we assume that in the configuration space \mathbb{M} the set of the first three coordinates (internal coordinates) $\{\bar{x}\} = (x^1, x^2, x^3) \in \mathcal{M}_t$, while the second set of three coordinates $(x^4, x^5, x^6) \in S^3$.

The coordinates which describe the internal motions are defined as follows:

$$\begin{aligned} x^1 &= \|\mathbf{x}_1\| \in [0, \infty), & x^2 &= \|\mathbf{x}_2\| \in [0, \infty), \\ x^3 &= \|\mathbf{x}_1 + \mathbf{x}_2\| = \sqrt{(x^1)^2 - 2x^1x^2 \cos \theta + (x^2)^2} \in [|x^1 - x^2|, |x^1 + x^2|], \end{aligned} \quad (7)$$

where θ is the angle between the vectors \mathbf{x}_1 and \mathbf{x}_2 (see figure) which in the Jacobi coordinates system coincides with the scattering angle.

The set of external coordinates (x^4, x^5, x^6) describes the rotational motion of a triangle (plane) and is uniquely related with the Euler angles $(\omega_1, \omega_2, \omega_3)$ the changing ranges of which are correspondingly defined as $(\omega_1, \omega_2) \in (-\pi, \pi]$ and $\omega_3 \in [0, \pi]$.

Now, Hamiltonian (5) can be represented in the form of bilinear expansion in the system of local coordinates (6):

$$\mathcal{H}(\mathbf{P}_\mathbf{x}; \mathbf{x}) = \frac{1}{2\mu_0} g^{ij}(\{x\}) p_i p_j, \quad i, j = 1, 2, \dots, 6, \quad \{x\} = (x^1, \dots, x^6), \quad (8)$$

where g^{ij} is a symmetric matrix which defines the metric of some Riemannian manifold; p_i are the components of decomposition of the 6D momentum in the local coordinate frame. Note that in (8) and below in the text by the dummy indices summation is implied.

Using representation (8), we can obtain equations of motion in the Hamiltonian form:

$$\frac{dx^i}{dt} = \frac{\partial \mathcal{H}}{\partial p_i} = \frac{1}{2\mu_0} g^{ij} p_j, \quad \frac{dp_i}{dt} = -\frac{\partial \mathcal{H}}{\partial x^i} = -\frac{1}{2\mu_0} g_{;i}^{kl} p_k p_l, \quad (9)$$

where $g_{;i}^{lj} = \partial_{x^i} g^{lj}$ and t is the usual time.

The linear infinitesimal element on the metric $g^{ij}(\{x\})$ can be defined by the following:

$$(ds)^2 = g_{ij}(\{x\}) dx^i dx^j, \quad (10)$$

where g_{ij} is the inverse to g^{ij} matrix.

In view of the physical reasoning, the metric of the Riemannian manifold will be conveniently defined as the energy surface of the body system (Lagrangian surface) which has the conformal Euclidean form:

$$g_{ij}(\{x\}) = g_{ij}(\{\bar{x}\}) = [E - U(\{x\})] \delta_{ij} = g(\{x\}) \delta_{ij}, \quad g^{ij} = g^{-1} \delta_{ij}, \quad (11)$$

where E is the total energy of the body system; in addition, for the metric we have the expression $g_{ij}(\{x\}) = g_{ij}(\{\bar{x}\})$ (see Eq. (2)).

Finally, we can write the explicit dependence of the total potential energy on the internal coordinates. Using Eqs.(3), (5) and (6), it is easy to obtain the following expression:

$$U(\{\bar{x}\}) = V(f_+(\{\bar{x}\}), f_-(\{\bar{x}\}), ax^1), \quad (12)$$

where $f_{\pm}(\{\bar{x}\}) = \sqrt{\sum_{k=1}^3 b_k^{\pm} (x^k)^2} > 0$; in addition, the following designations are made:

$$a = \sqrt{\frac{\mu_0}{\mu_2}}, \quad b_1^{\pm} = \frac{\mu_0}{\mu_2} \left(1 \pm \lambda_{\pm} \sqrt{\frac{\mu_2}{\mu_3}} \right), \quad b_2^{\pm} = \frac{\mu_0}{\mu_2} \left(1 \pm \lambda_{\pm} \sqrt{\frac{\mu_3}{\mu_2}} \right), \\ b_3^{\pm} = \mp \lambda_{\pm} \frac{\mu_0}{\sqrt{\mu_2 \mu_3}}.$$

Let us note that the bilinear form under the square root is positive by definition regardless of coefficients' values b_k^{\pm} , where $k = 1, 2, 3$.

2. THE EQUATION OF MOTION FOR GEODESIC TRAJECTORIES

Since the Hamiltonian \mathcal{H} describes a conservative system, the energy is an integral of motion; hence the equation $\mathcal{H}(\mathbf{P}_x; \mathbf{x}) = E = \text{const}$ determines the 11-dimensional energy hypersurface in the 12-dimensional phase space. As is well known, the phase trajectories (9) which describe the behavior of Hamiltonian system (8) may be presented as geodesic trajectories of the Riemannian manifold (see [26, 27]) given generally in a subspace $\Xi \subset \mathcal{M}_t$ defined by the inequality $U(\{\bar{x}\} \in \Xi) < E$.

The geodesic equations on the Riemannian manifold can be derived using the variational principle of Maupertuis [24, 25] and are obviously equivalent to system of equations (9):

$$\ddot{x}^i + \Gamma_{jk}^i \dot{x}^j \dot{x}^k = 0, \quad i, j, k = 1, \dots, 6, \quad (13)$$

where $\dot{x}^i = dx^i/ds$ and $\ddot{x}^i = d^2x^i/ds^2$; in addition, Γ_{jk}^i designates Christoffel symbol:

$$\Gamma_{jk}^i(\{x\}) = \frac{1}{2} g^{il} (\partial_k g_{lj} + \partial_j g_{kl} - \partial_l g_{jk}), \quad \partial_{\alpha} \equiv \partial_{x^{\alpha}}. \quad (14)$$

Taking into account (10) and (14), we can obtain the following system of six ordinary differential equations which describe the motion of the effective mass μ_0

on the configuration manifold $\mathbb{M} \subset \mathbb{R}^6$:

$$\begin{aligned}
\ddot{x}^1 &= -a_1 \left\{ (\dot{x}^1)^2 - \sum_{i \neq 1, i=2}^6 (\dot{x}^i)^2 \right\} - 2\dot{x}^1 \{a_2 \dot{x}^2 + a_3 \dot{x}^3\}, \\
\ddot{x}^2 &= -a_2 \left\{ (\dot{x}^2)^2 - \sum_{i=1, i \neq 2}^6 (\dot{x}^i)^2 \right\} - 2\dot{x}^2 \{a_3 \dot{x}^3 + a_1 \dot{x}^1\}, \\
\ddot{x}^3 &= -a_3 \left\{ (\dot{x}^3)^2 - \sum_{i=1, i \neq 3}^6 (\dot{x}^i)^2 \right\} - 2\dot{x}^3 \{a_1 \dot{x}^1 + a_2 \dot{x}^2\}, \\
\ddot{x}^4 &= -2\dot{x}^4 \{a_1 \dot{x}^1 + a_2 \dot{x}^2 + a_3 \dot{x}^3\}, \\
\ddot{x}^5 &= -2\dot{x}^5 \{a_1 \dot{x}^1 + a_2 \dot{x}^2 + a_3 \dot{x}^3\}, \\
\ddot{x}^6 &= -2\dot{x}^6 \{a_1 \dot{x}^1 + a_2 \dot{x}^2 + a_3 \dot{x}^3\},
\end{aligned} \tag{15}$$

where the following denotations are made:

$$\begin{aligned}
g(\{\bar{x}\}) &= g_{11}(\{\bar{x}\}) = \dots = g_{66}(\{\bar{x}\}), \quad a_k(\{\bar{x}\}) = (1/2)\partial_k \ln g(\{\bar{x}\}), \\
& \quad k = 1, 2, 3.
\end{aligned}$$

In system (15), the last three equations are solved exactly:

$$\dot{x}^l = J_l/g(\{\bar{x}\}), \quad J_l = \text{const}_l, \quad l = 4, 5, 6. \tag{16}$$

Let us note that J_4, J_5 and J_6 are the integrals of motion. They can be interpreted as projections of the total angular momentum of the three-body system onto corresponding axes which are clearly defined by the initial conditions.

Finally, substituting (16) into Eqs.(15), we obtain the following system of nonlinear second-order differential equations which describe dynamics of the three-body system on the *internal space* \mathcal{M}_t taking into account rotations of the triangle on the external space S^3 :

$$\begin{aligned}
\ddot{x}^1 &= -a_1 \{(\dot{x}^1)^2 - (\dot{x}^2)^2 - (\dot{x}^3)^2 - (J/g)^2\} - 2\dot{x}^1 \{a_2 \dot{x}^2 + a_3 \dot{x}^3\}, \\
\ddot{x}^2 &= -a_2 \{(\dot{x}^2)^2 - (\dot{x}^3)^2 - (\dot{x}^1)^2 - (J/g)^2\} - 2\dot{x}^2 \{a_3 \dot{x}^3 + a_1 \dot{x}^1\}, \\
\ddot{x}^3 &= -a_3 \{(\dot{x}^3)^2 - (\dot{x}^1)^2 - (\dot{x}^2)^2 - (J/g)^2\} - 2\dot{x}^3 \{a_1 \dot{x}^1 + a_2 \dot{x}^2\},
\end{aligned} \tag{17}$$

where $J = \sqrt{J_4^2 + J_5^2 + J_6^2} = \text{const}$ is the integral of motion of the total angular momentum of the three-body system.

Thus, we have proved that the general 3D classical three-body scattering problem can be reduced to the problem of solution of the three nonlinear second-order differential equations on the tangential bundle \mathcal{M}_t of the Lagrange manifold $\mathcal{M} = [\{\bar{x}\} \equiv (x^1, x^2, x^3) \in \mathcal{M}_t; g_{ij} = (E - U\{\bar{x}\})\delta_{ij} > 0]$.

Many important properties of the dynamical system can be studied by means of investigation of the behavior of linear deviations $\eta^i = \tilde{x}^i - x^i$ between close geodesic trajectories $\tilde{l} = \tilde{l}(\tilde{x}^1, \tilde{x}^2, \tilde{x}^3)$ and $l = l(x^1, x^2, x^3)$. Recall that the linear deviation satisfies the equation [24]

$$\mathcal{D}_s^2 \eta^i = -R_{jkl}^i(\{\bar{x}\}) \dot{x}^j \eta^k \dot{x}^l, \quad i, j, k, l = 1, 2, \dots, 6, \quad (18)$$

where $R_{jkl}^i(\{\bar{x}\}) = \partial_k \Gamma_{lj}^i - \partial_l \Gamma_{jk}^i + \Gamma_{k\lambda}^i \Gamma_{lj}^\lambda - \Gamma_{l\lambda}^i \Gamma_{jk}^\lambda$ is the Riemann tensor and $\mathcal{D}_s A^i \equiv \mathcal{D}A^i / \mathcal{D}s = \dot{A}^i + \Gamma_{jl}^i(\{\bar{x}\}) \dot{x}^j A^l$ denotes the covariant derivative.

The explicit form of the deviation equations is very difficult to derive from (18). However, this can be done easily by way of expansion of equations system (17) on degrees of deviations keeping only the linear terms of deviation:

$$\begin{aligned} \ddot{\eta}^1 &= -\{c_{1l}[(\dot{x}^1)^2 - (\dot{x}^2)^2 - (\dot{x}^3)^2] - 2\dot{x}^1(c_{2l}\dot{x}^2 + c_{3l}\dot{x}^3) + (2a_1 a_l - g^{-2})J^2\}\eta^l - \\ &\quad - 2a_1\{\dot{x}^1\dot{\eta}^1 - \dot{x}^2\dot{\eta}^2 - \dot{x}^3\dot{\eta}^3\} - 2\dot{\eta}^1\{a_2\dot{x}^2 + a_3\dot{x}^3\} - 2\dot{x}^1\{a_2\dot{\eta}^2 + a_3\dot{\eta}^3\}, \\ \ddot{\eta}^2 &= -\{c_{2l}[(\dot{x}^2)^2 - (\dot{x}^3)^2 - (\dot{x}^1)^2] - 2\dot{x}^2(c_{3l}\dot{x}^3 + c_{1l}\dot{x}^1) + (2a_2 a_l - g^{-2})J^2\}\eta^l - \\ &\quad - 2a_2\{\dot{x}^2\dot{\eta}^2 - \dot{x}^3\dot{\eta}^3 - \dot{x}^1\dot{\eta}^1\} - 2\dot{\eta}^2\{a_3\dot{x}^3 + a_1\dot{x}^1\} - 2\dot{x}^2\{a_3\dot{\eta}^3 + a_1\dot{\eta}^1\}, \quad (19) \\ \ddot{\eta}^3 &= -\{c_{3l}[(\dot{x}^3)^2 - (\dot{x}^1)^2 - (\dot{x}^2)^2] - 2\dot{x}^3(c_{1l}\dot{x}^1 + c_{2l}\dot{x}^2) + (2a_3 a_l - g^{-2})J^2\}\eta^l - \\ &\quad - 2a_3\{\dot{x}^3\dot{\eta}^3 - \dot{x}^1\dot{\eta}^1 - \dot{x}^2\dot{\eta}^2\} - 2\dot{\eta}^3\{a_1\dot{x}^1 + a_2\dot{x}^2\} - 2\dot{x}^3\{a_1\dot{\eta}^1 + a_2\dot{\eta}^2\}, \end{aligned}$$

where $c_{k,l} = \partial_l a_k$ and $k, l = 1, 2, 3$.

While analyzing system of equations (19), we can construct the explicit form of the Riemann tensor. It is obvious that system of linear equations for deviations (19) can be solved together with nonlinear equations of geodesics (17).

3. THE RESTRICTED THREE-BODY PROBLEM

Using representation for the Hamiltonian (8) and solutions (16), we can find the reduced Hamiltonian on the *internal space* \mathcal{M}_t :

$$\bar{\mathcal{H}}(\{\bar{x}\}; \{\dot{\bar{x}}\}) = \frac{\mu_0}{2g(\{\bar{x}\})} \{u^2 + v^2 + w^2 + (J/g(\{\bar{x}\}))^2\}, \quad \{\dot{\bar{x}}\} = (u, v, w), \quad (20)$$

where $(\{\bar{x}\}, \{\dot{\bar{x}}\}) \in \mathcal{M}_t$.

As is easy to see, equations system (17) can be transformed to the system of nonlinear differential equations of Riccati type:

$$\begin{aligned} \dot{u} + a_1\{u^2 - v^2 - w^2 - (J/g)^2\} + 2\{a_2v + a_3w\}u &= 0, & u = \dot{x}^1, \\ \dot{v} + a_2\{v^2 - w^2 - u^2 - (J/g)^2\} + 2\{a_3w + a_1u\}v &= 0, & v = \dot{x}^2, \\ \dot{w} + a_3\{w^2 - u^2 - v^2 - (J/g)^2\} + 2\{a_1u + a_2v\}w &= 0, & w = \dot{x}^3. \end{aligned} \quad (21)$$

System of equations (21) describes the dynamics of a general three-body system on the Lagrange manifold \mathcal{M} and, obviously, their solutions must satisfy the energy conservation law: $\bar{\mathcal{H}}(\{\bar{x}\}; \{\dot{\bar{x}}\}) = E = \text{const}$. Note that this equation defines the 5-dimensional energy hypersurface in the reduced 6-dimensional phase space.

An important class of solutions for the three-body problem is the restricted problem (123)* (see the scheme of scattering). Some basic properties of this problem can be studied without solving equations of motion (17) (or (21)).

Using Eqs. (21), we can derive conditions at which formation of stable configurations for a three-body system is possible.

The first condition which must be satisfied for stable configuration of a body system is obviously the condition of absence of external forces:

$$\nabla \bar{\mathcal{H}}(\{\bar{x}\}; \{\dot{\bar{x}}\}) = 0, \quad \nabla = g^{ij} \partial_j = g^{-1} \sum_{j=1}^3 \partial_j, \quad \partial_j = \partial / \partial x^j. \quad (22)$$

Substituting (20) into (22) with account of the definition of coefficients a_i (see (15)), we can find the following system of algebraic equations:

$$a_1(\{\bar{x}\}) = 0, \quad a_2(\{\bar{x}\}) = 0, \quad a_3(\{\bar{x}\}) = 0. \quad (23)$$

Solving system (23), we can find sets of stationary points $\{\bar{x}\}_i$ where $i = 0, 1, \dots$

It is obvious that from these sets of points stable configurations will form only those for which the following conditions are satisfied:

$$\begin{aligned} \partial_{11}^2 \bar{\mathcal{H}}(\{\bar{x}\}_{0i}; \{\dot{\bar{x}}\}_{0i}) &> 0, \quad \det(\partial_{ij}^2 \bar{\mathcal{H}}(\{\bar{x}\}_{0i}; \{\dot{\bar{x}}\}_{0i})) > 0, \\ \det(\partial_{kl}^2 \bar{\mathcal{H}}(\{\bar{x}\}_{0i}; \{\dot{\bar{x}}\}_{0i})) &> 0, \end{aligned} \quad (24)$$

where $i, j = 1, 2$ and $k, l = 1, 2, 3$; in addition, in (24) designation $\partial_{kl}^2 = \partial^2 / \partial x^k \partial x^l$ is made. However, system of equations (23), together with conditions (24), defines stable configurations $(\{\bar{x}\}_{0i}; \{\dot{\bar{x}}\}_{0i} = 0)$ of motionless bodies. Note that these stable stationary configurations are interesting in that they can serve as bases for constructing homographic solutions (the solutions which conserve the configuration of bodies during the time). In other words, near the stationary points $\{\bar{x}\}_i \approx \{\bar{x}\}_{0i}$ configuration of bodies should be moving freely.

The latter means that we can ignore the first derivatives in Eqs.(21) and write them in the form of algebraic equations:

$$\begin{aligned} a_1\{u^2 - v^2 - w^2 - (J/g)^2\} + 2\{a_2v + a_3w\}u &= 0, \\ a_2\{v^2 - w^2 - u^2 - (J/g)^2\} + 2\{a_3w + a_1u\}v &= 0, \\ a_3\{w^2 - u^2 - v^2 - (J/g)^2\} + 2\{a_1u + a_2v\}w &= 0. \end{aligned} \quad (25)$$

If we assume that coefficients satisfy the following limit transitions:

$$\lambda_{lk} = \lim_{\{\bar{x}\}_i \rightarrow \{\bar{x}\}_{0i}} a_k/a_l, \quad \lambda_{lk} = \lambda_{kl}^{-1}, \quad k, l = 1, 2, 3,$$

in this case system of equations (25) at the stationary point $\{\bar{x}\}_{0i}$ can be written in the form

$$\begin{aligned} u^2 - v^2 - w^2 - \lambda_0 + 2(\lambda_{12}v + \lambda_{13}w)u &= 0, \\ v^2 - w^2 - u^2 - \lambda_0 + 2(\lambda_{23}w + \lambda_{21}u)v &= 0, \\ w^2 - u^2 - v^2 - \lambda_0 + 2(\lambda_{31}u + \lambda_{32}v)w &= 0, \end{aligned} \quad (26)$$

where $\lambda_0 = (J/g(\{\bar{x}\}_{0i}))^2 = \text{const}_i \geq 0$.

Solving system of equations (26), we can find, in the general case, eight sets of solutions for velocities $\{\dot{\bar{x}}\}_{0i}^k$, where $k = 1, \dots, 8$. The existence of sets of real solutions will mean that for the body system with account of rotations on Euler angles there are homographic solutions. In the case when there is at least one set of solutions for system of equations (26), it is important to seek solutions to (25) near a stationary point with consideration of conditions (24). By these computations, we can find a region in the phase space where the coupled three-body system (123)* depending on specific conditions can be in the stable or quasistable equilibrium state.

4. THE INITIAL AND ASYMPTOTIC CONDITIONS OF THE THREE-BODY SCATTERING PROBLEM

For the solution of equations system (17) and interpretation of its results from the point of view of multichannel scattering, it is necessary to define the initial conditions of the problem and analyze the asymptotic behavior of these solutions. Obviously, for the solution of the scattering problem using the example of a specific system, the initial position and velocity of the imaginary mass μ_0 on the configuration space \mathbb{M} must be defined. However, for the qualitative investigation of the scattering problem the initial conditions can be defined from the physical considerations on the reduced space more clearly on the bundle \mathcal{M}_t of the Lagrange manifold \mathcal{M} .

As is seen from the scheme of multichannel scattering given at the beginning, the system of three bodies is located in the subspace (*in*) where particle 1 is in the free state, while the other two particles 2 and 3 form the bound state (23). In terms of coordinates of the *internal space* \mathcal{M}_t , this asymptotic state is defined by the following characteristic distances:

$$x^1 \leq l_{23} = \text{const} > 0, \quad x^2 \rightarrow \infty, \quad x^3 \rightarrow \infty, \quad (27)$$

where l_{23} denotes the oscillation amplitude of imaginary point with the mass μ_0 , which is proportional to the distance between particles 2 and 3 when pair (23) is in the equilibrium. In addition, projections of the initial velocity of the imaginary point will be defined as follows:

$$\dot{x}^1 = |v_1| \leq v_{01} = \text{const} > 0, \quad \dot{x}^2 = \dot{x}^3 = v_0, \quad (28)$$

where v_{01} and v_0 are the maximum velocity at oscillations by the coordinate x^1 and the velocity of translational motion of the imaginary point, respectively. The total energy of the body system is an important integral of motion which can be written with the help of initial conditions:

$$E = \frac{\mu_0}{2}[(v_{01}^2 + 2v_0^2) + 2J^2] + V_{23}(l_{23}), \quad (29)$$

where V_{23} denotes the interaction potential between bodies 2 and 3.

Thus, (27) and (29) are the necessary initial conditions for the solution of system of nonlinear equations (17) (equivalent to system (21)) which describes multichannel scattering in a three-body system.

Let us note that we can analyze behavior of geodesic trajectories in the limit $s \rightarrow \infty$ and find full information on the outcome of the collision.

In particular, after the collision of particles the geodesic trajectory comes to one of (*out*) asymptotic subspaces which are characterized by specific configurations of particles (see the scheme of scattering):

a) in the case when $f_-(\{x\}) \rightarrow \infty$, $f_+(\{x\}) \rightarrow \infty$ and $x^1 \leq l_{23}$, we have the outcome 1 + (23) (the excitation);

b) when $(f_-(\{x\}), f_+(\{x\})) \rightarrow \infty$ and $x^1 \rightarrow \infty$, the outcome of the process is the dissociation 1 + 2 + 3 (all the particles are free);

c) when $f_-(\{x\}) \leq l_{12} = \text{const}$, $f_+(\{x\}) \rightarrow \infty$ and $x^1 \rightarrow \infty$, the outcome is the regrouping of particles with formation of the new bound state (12) + 3, where l_{12} is the scaled distance between the particles of pair (12) at the equilibrium;

d) when $f_-(\{x\}) \rightarrow \infty$, $f_+(\{x\}) \leq l_{13} = \text{const}$ and $x^1 \rightarrow \infty$, the outcome is new regrouping of the particles (13) + 2, where l_{13} is the scaled distance between the particles of pair (13).

Note that all processes which go across a phase of formation of the transition complex (123)* eventually come to one of the four aforementioned asymptotic subspaces.

CONCLUSION

As was shown by Poincare, the three-body problem is generally a nonintegrable system where the system of bodies in the phase space often demonstrates chaotic behavior. It means that the small differences in the initial conditions produce very significant changes in the motion of the system on relatively smallish intervals of time, which makes practically impossible the prediction of evolution of bodies system in the phase space. The latter in turn means that any small error at calculations of the three-body problem can develop in a short time into an enormous mistake. Based on the foregoing, the reduction of the dimensionality of the general classical three-body problem is a mathematical problem of great importance. It should be noted that for the solution of this problem a lot of effort has been made, but the maximal possible reduction of dimensionality of the three-body and N -body problem is achieved only when the motion of bodies is constrained on a plane [28].

As is shown by this study, the problem of reducing the general three-body problem can be successfully solved if the dynamical problem is formulated as a geodesic trajectories problem on the energy surface of bodies system. Note that in this case the dynamics of the three-body system is described in the *internal space* \mathcal{M}_t by the system of three nonlinear ODEs of canonical form (17) instead of the usual six ODEs. System of equations (17) simply reduces to a system of Riccati equations, which is in stationary points correspondingly transformed into system of algebraic equations (26). If the interaction potential between the bodies is defined, we can solve system of equations (26) and find all homographic solutions of a moving three-body system. In the paper, the initial and asymptotic conditions of the multichannel scattering problem are also discussed in detail.

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